

FIG. 1.

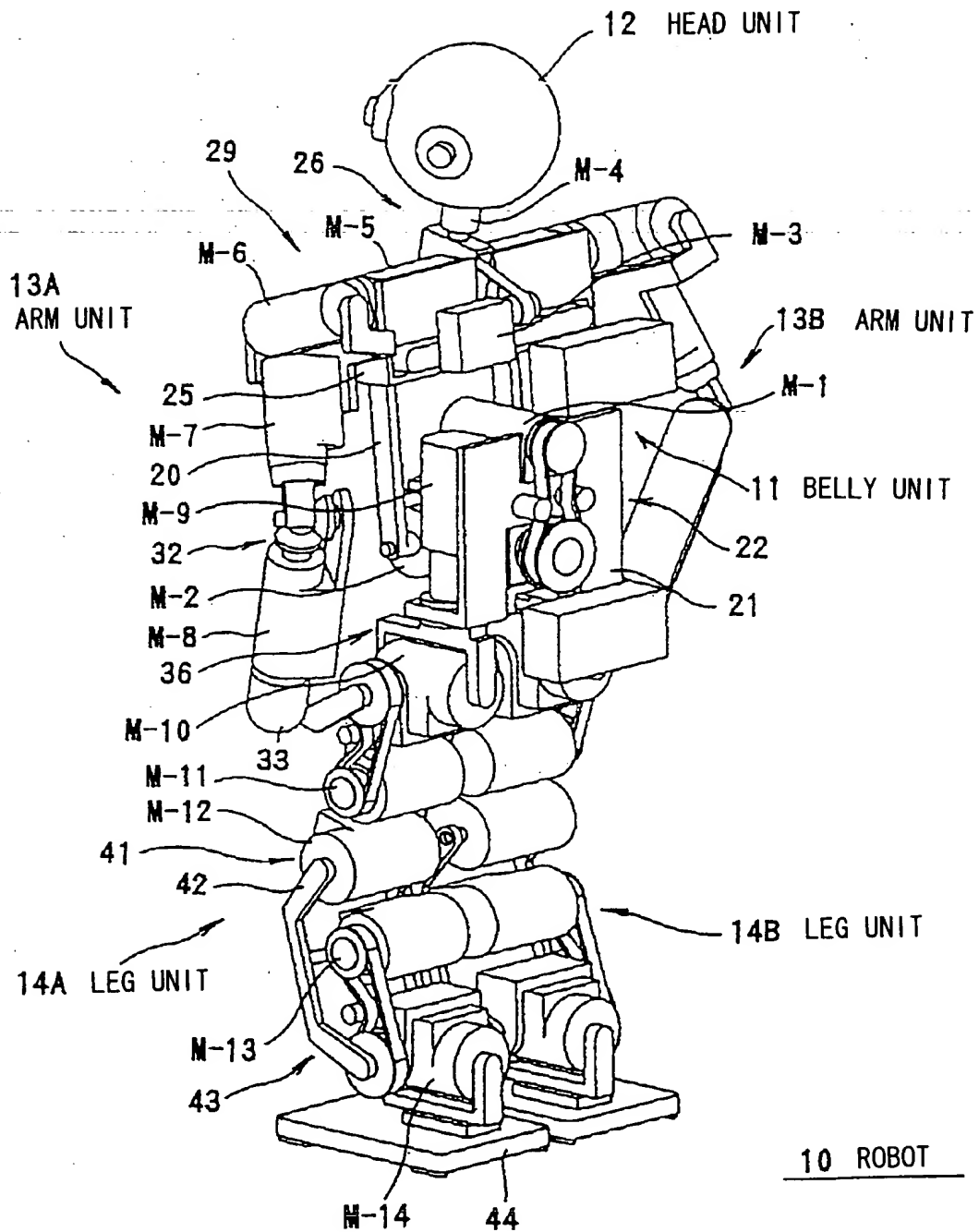


FIG. 2

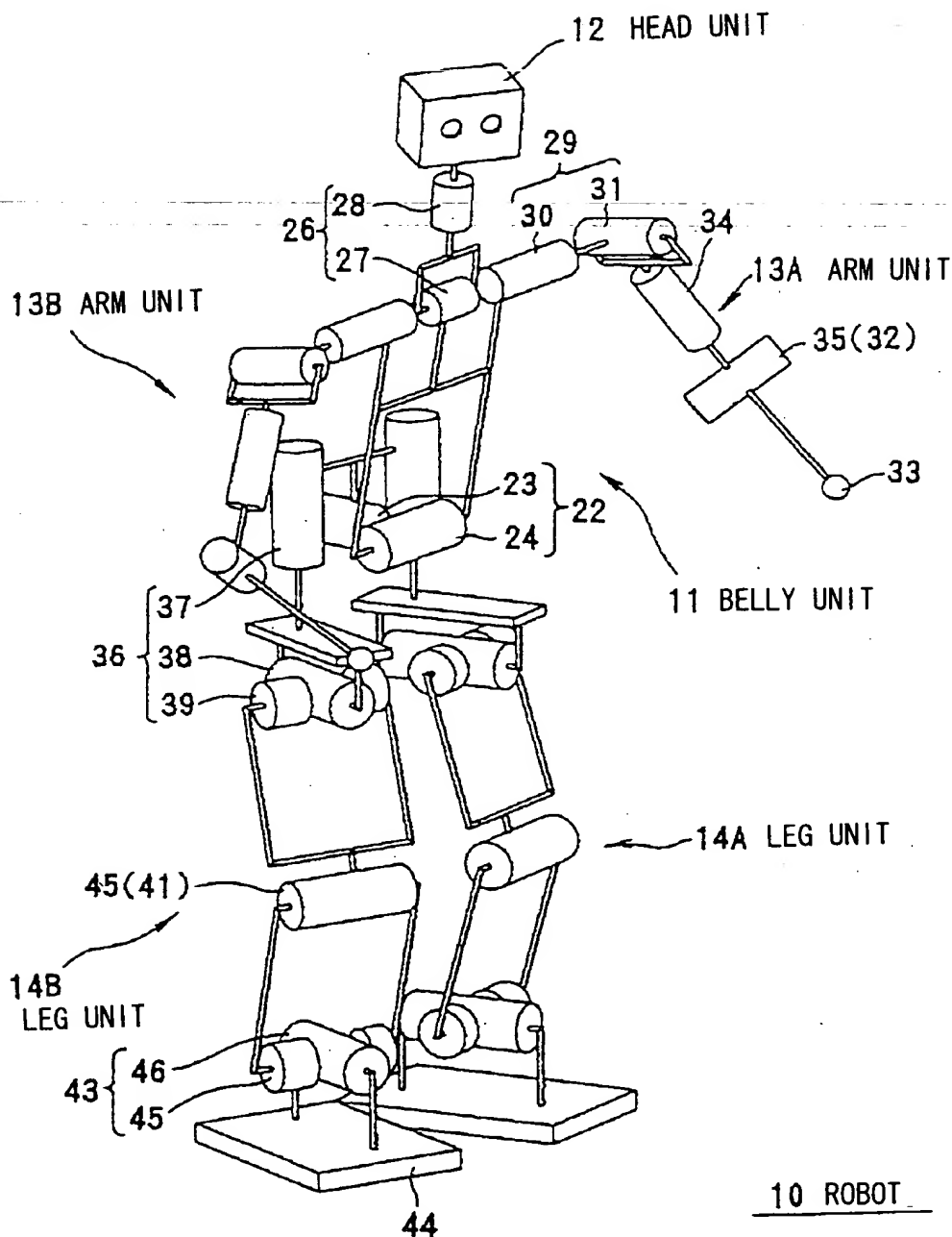


FIG. 3

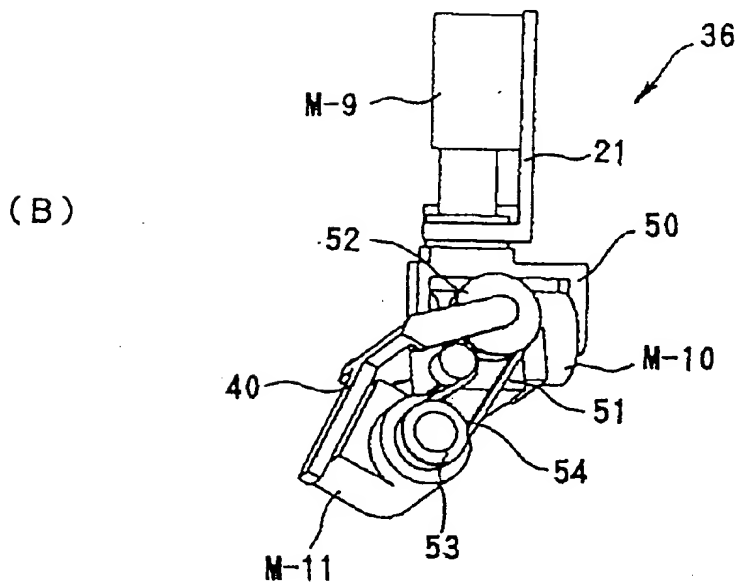
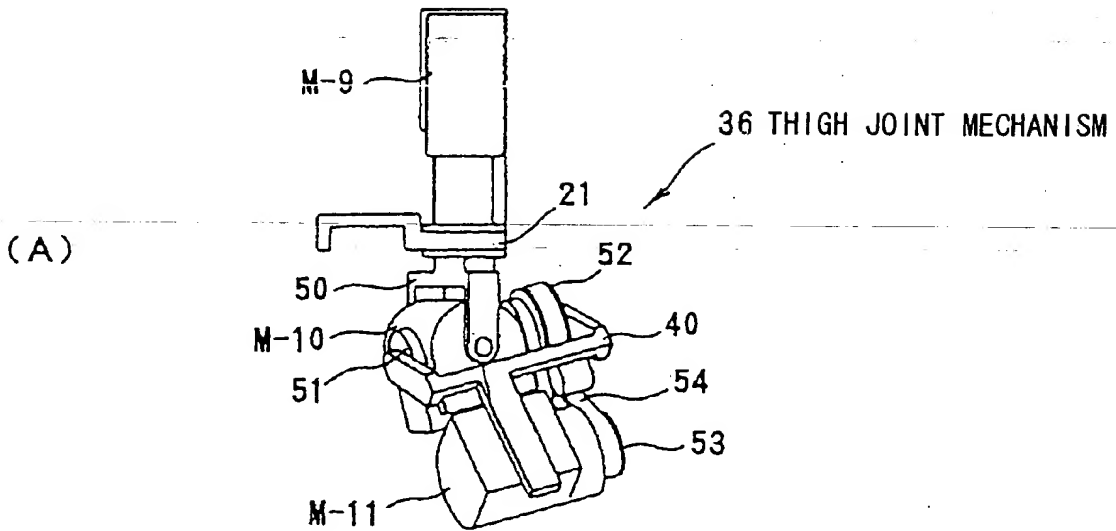


FIG. 4

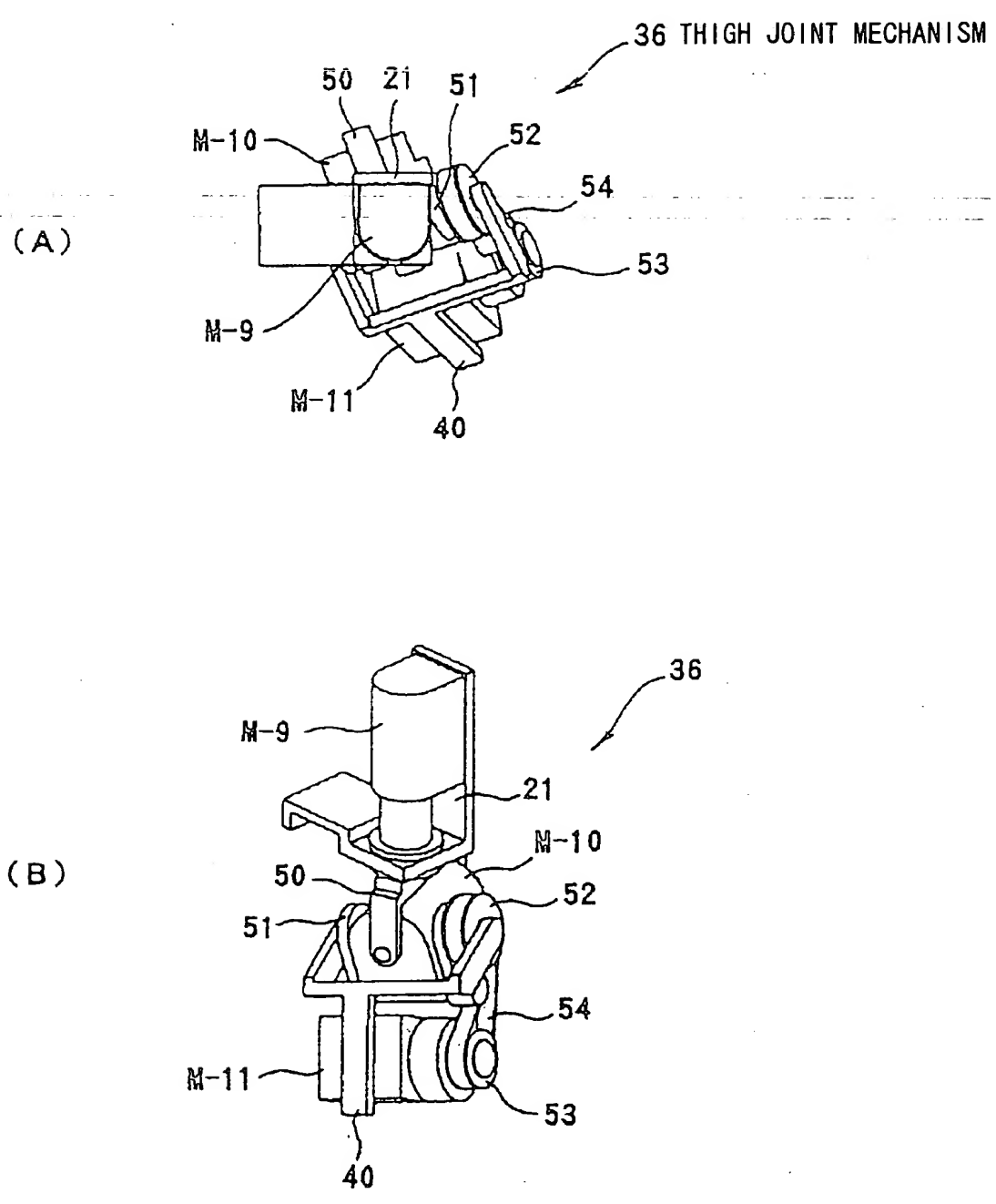


FIG. 5

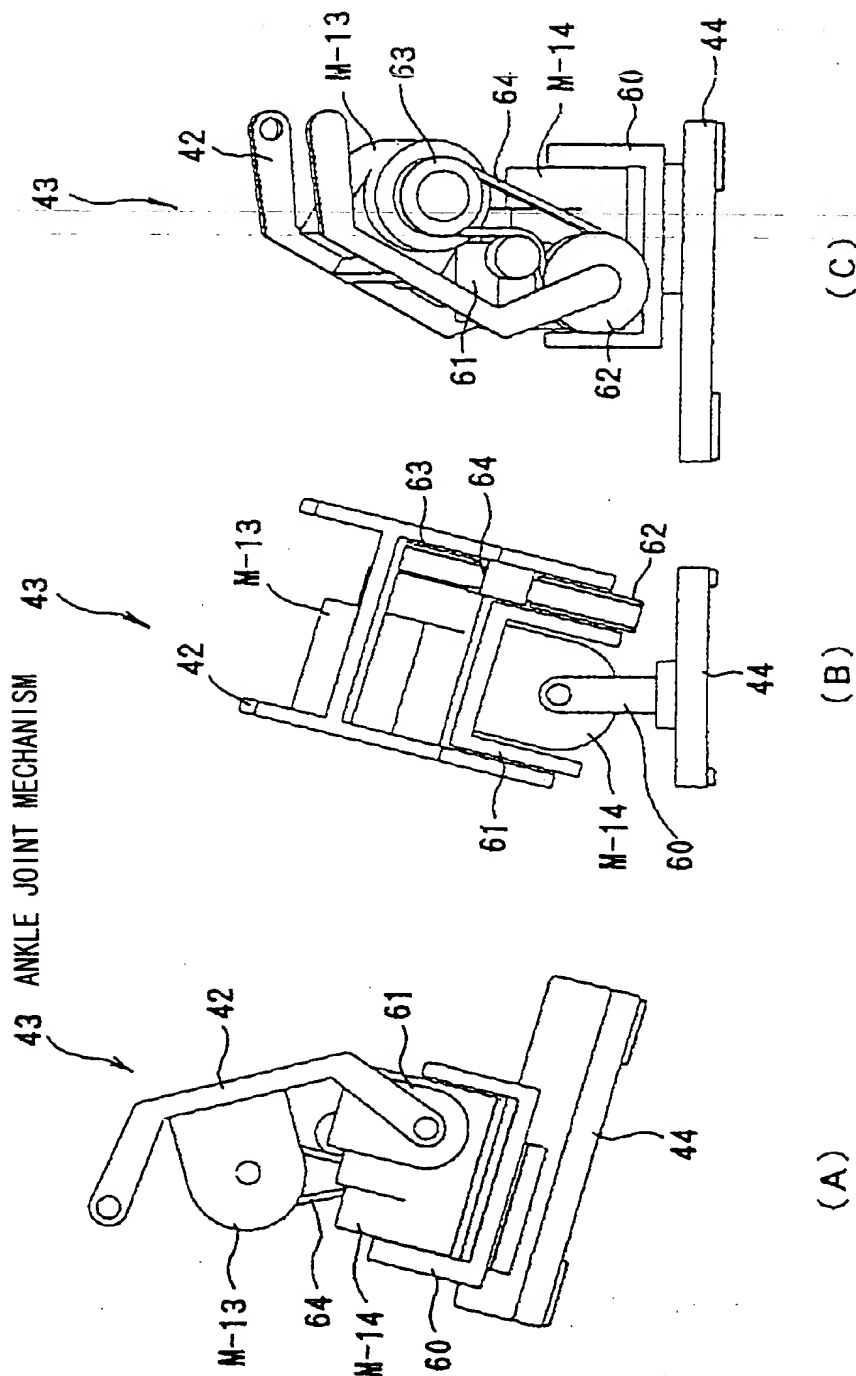


FIG. 6

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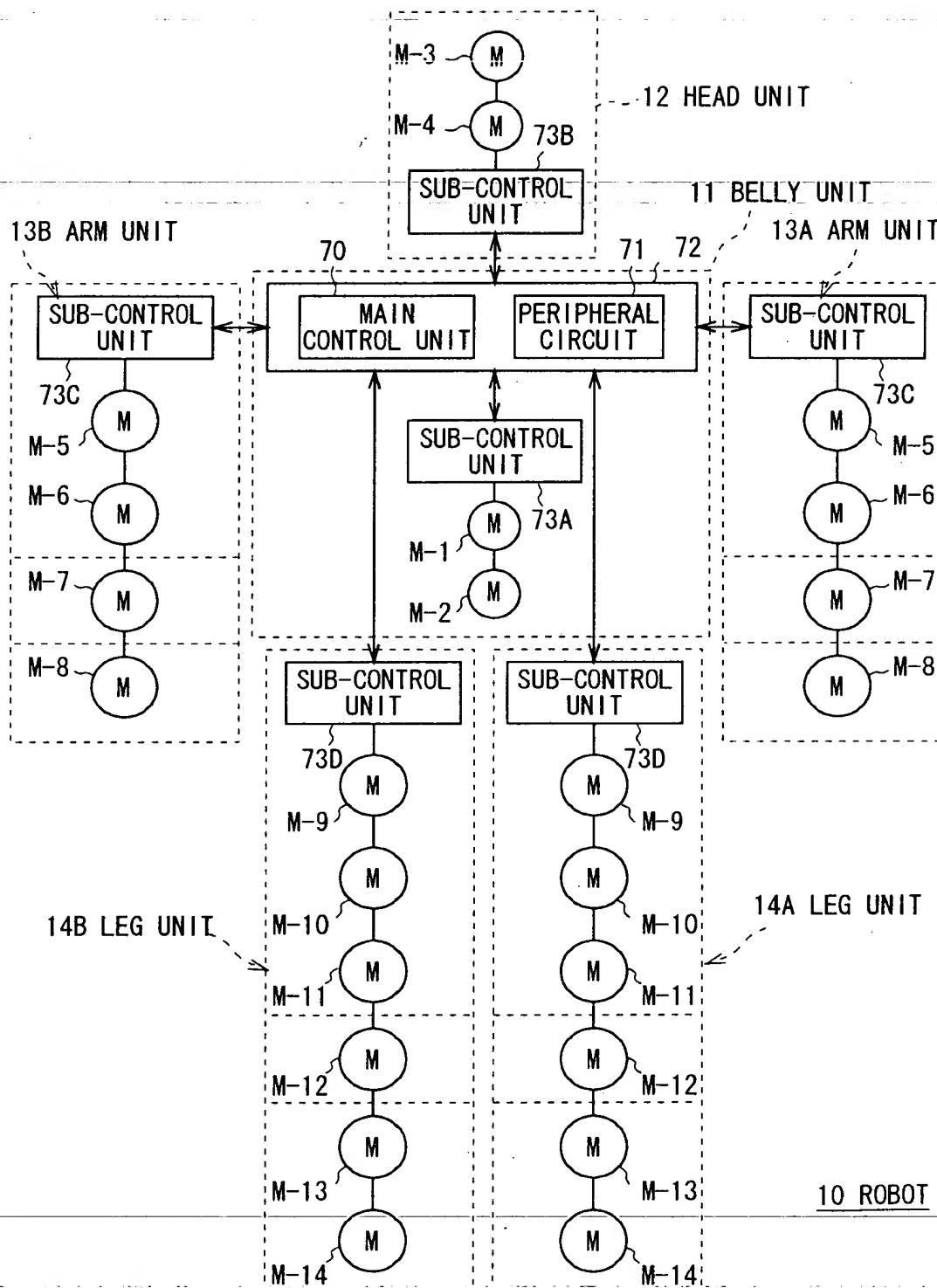


FIG. 7

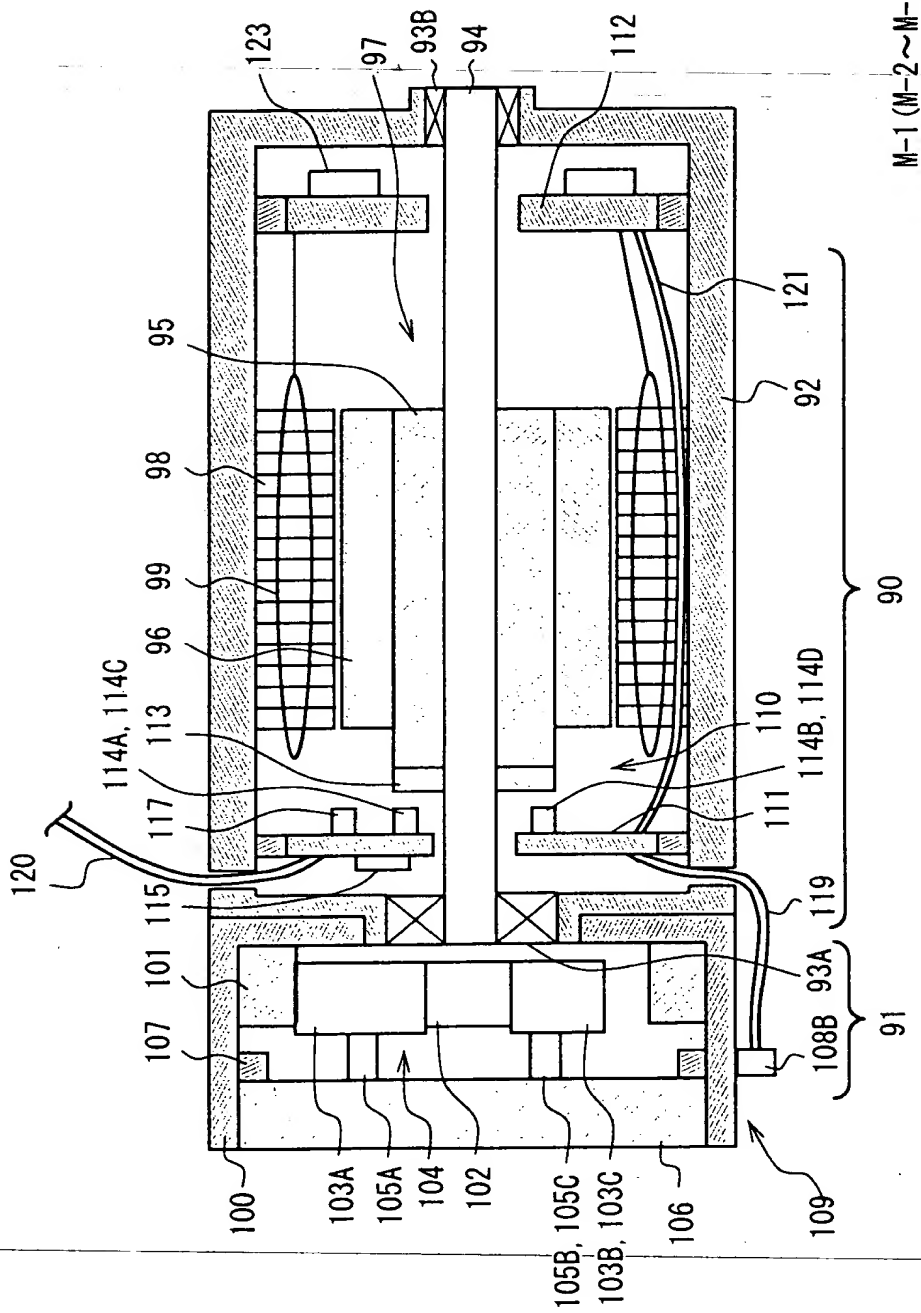


FIG. 9

M-1 (M-2~M-14)

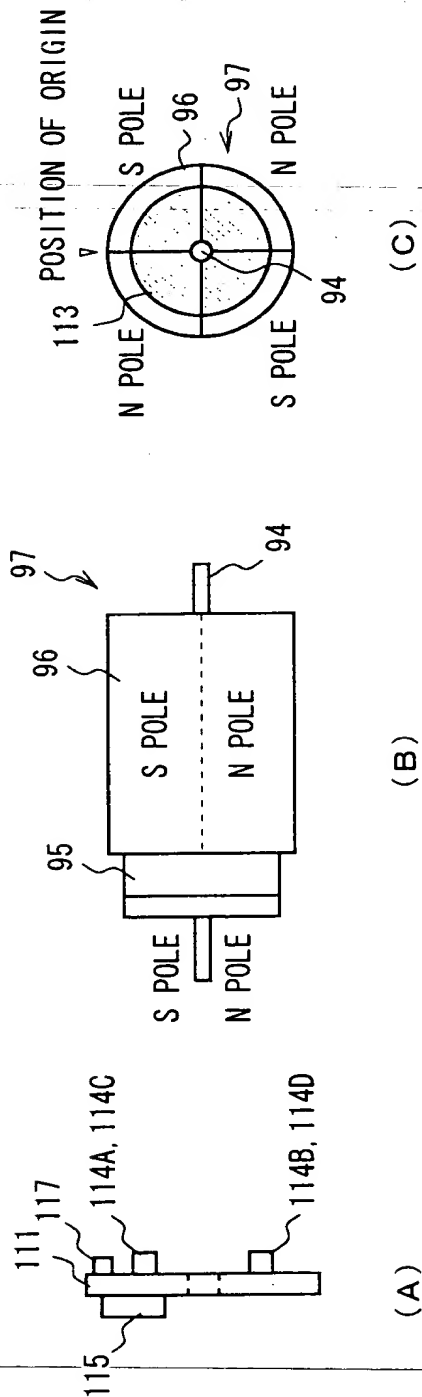


FIG. 10

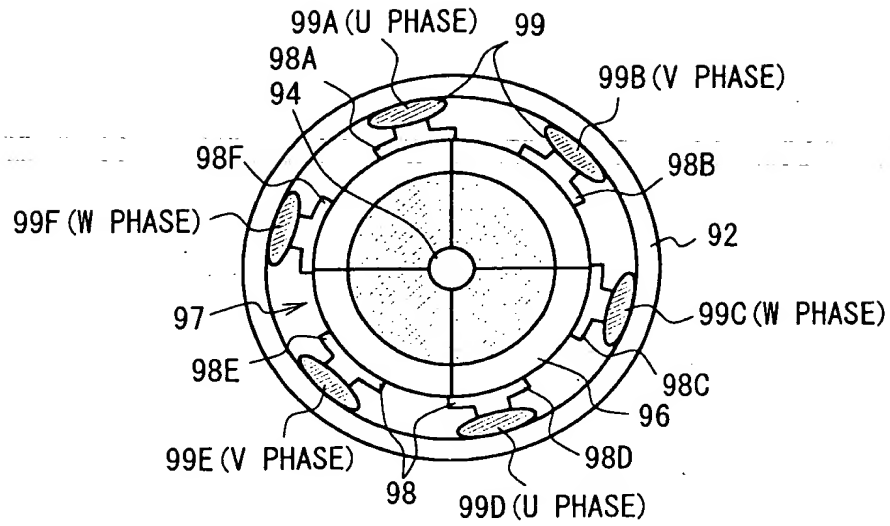


FIG. 11

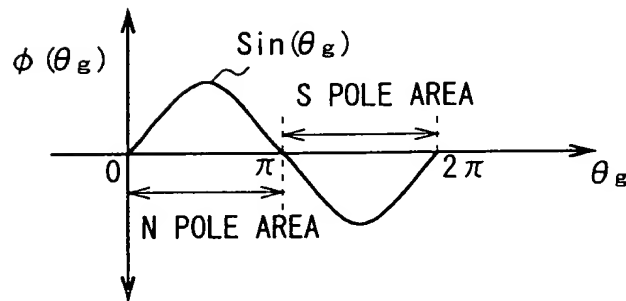
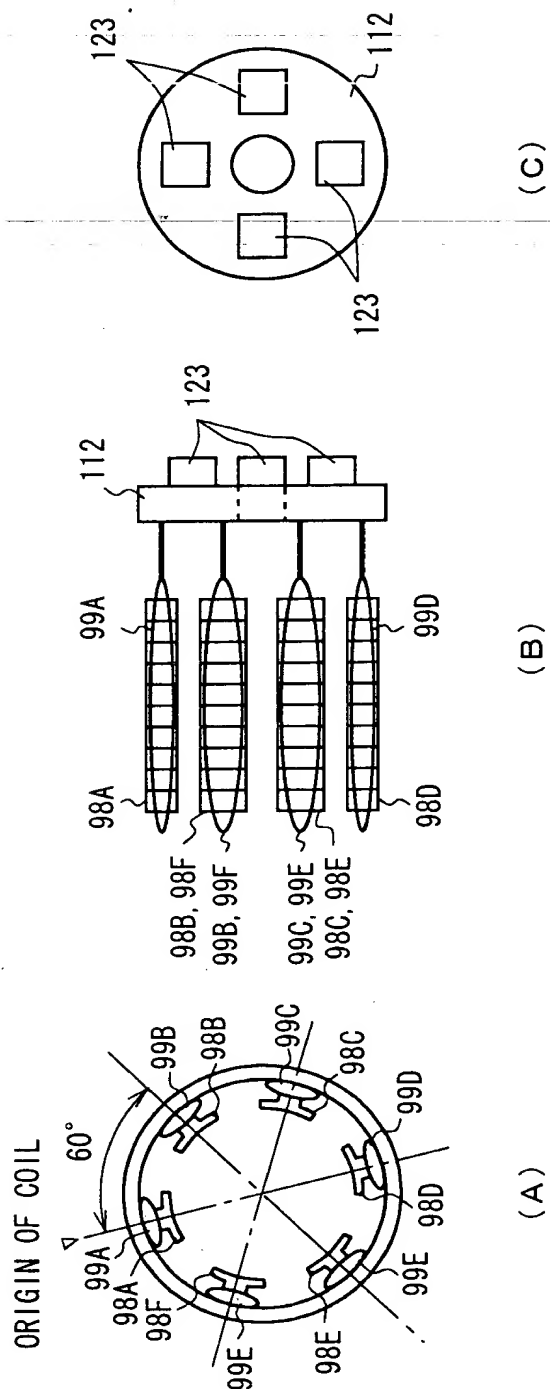


FIG. 14



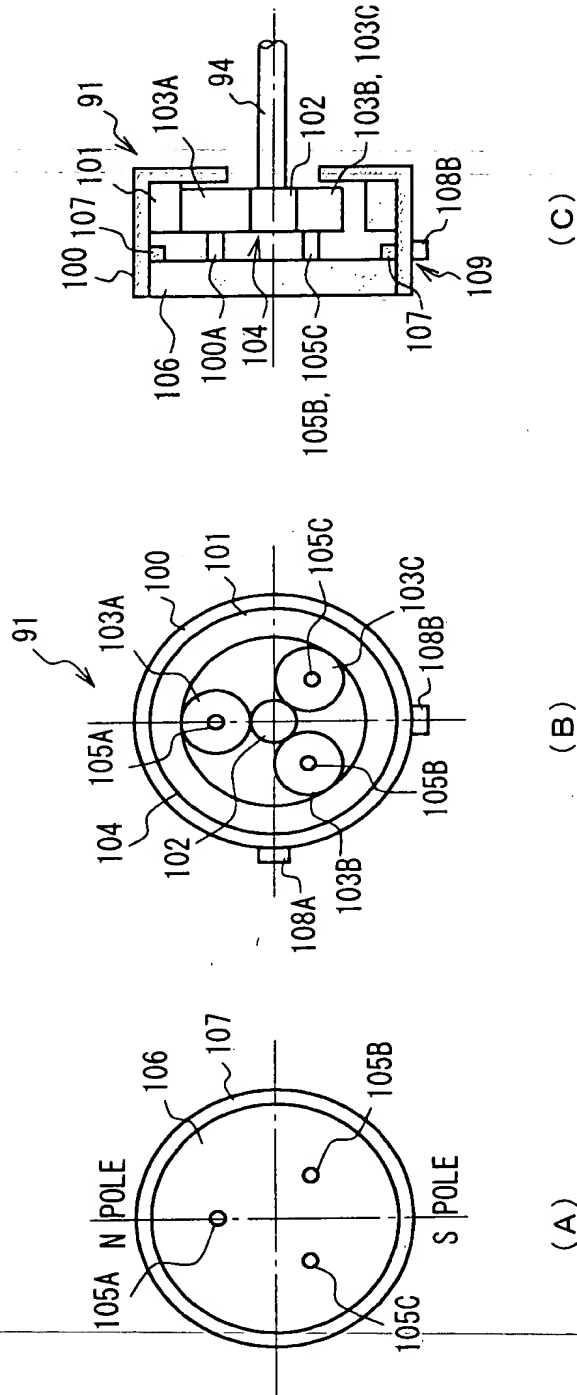


FIG. 13

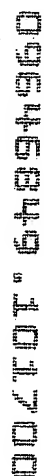
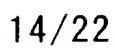
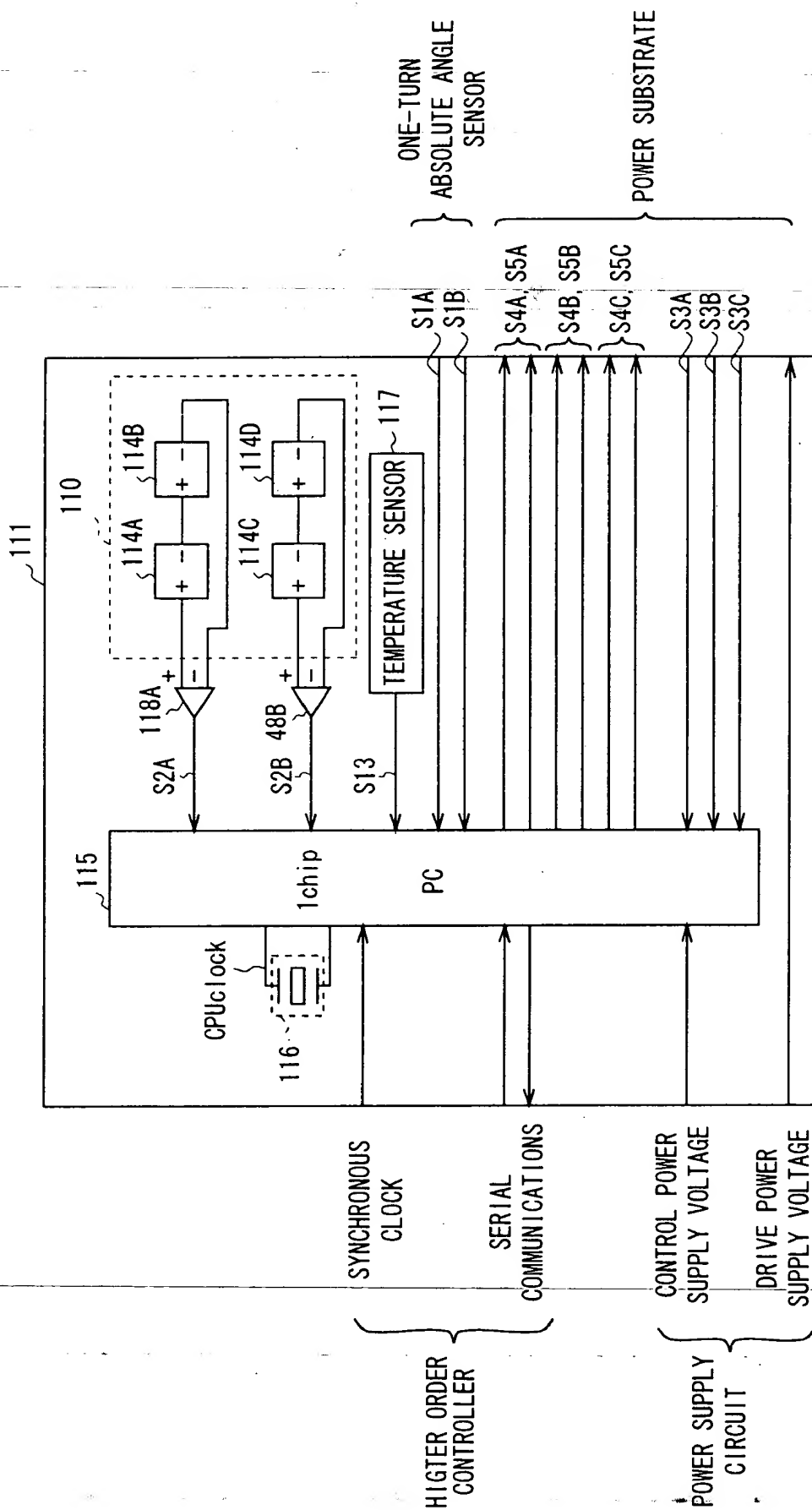


FIG. 16





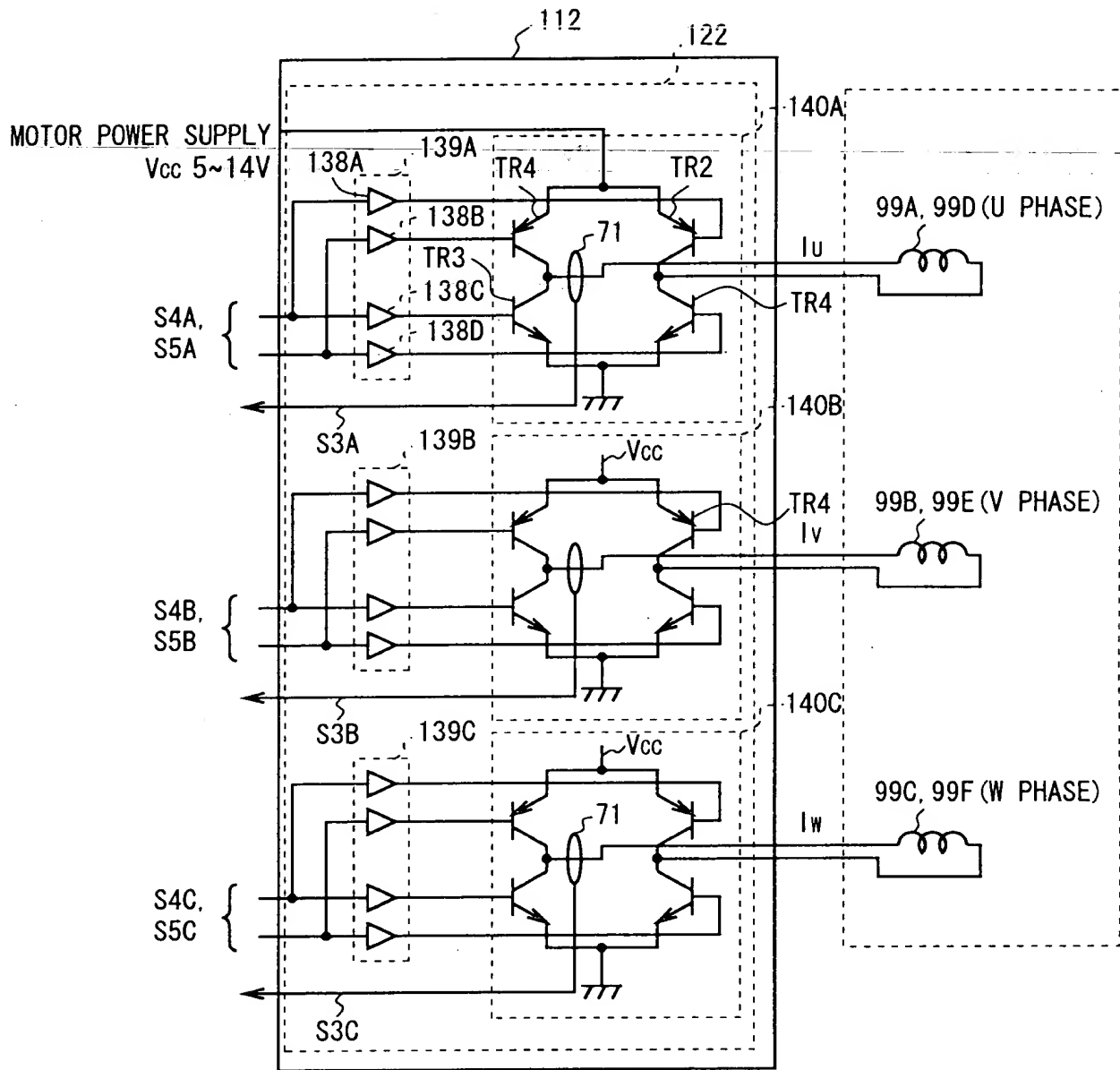


FIG. 18

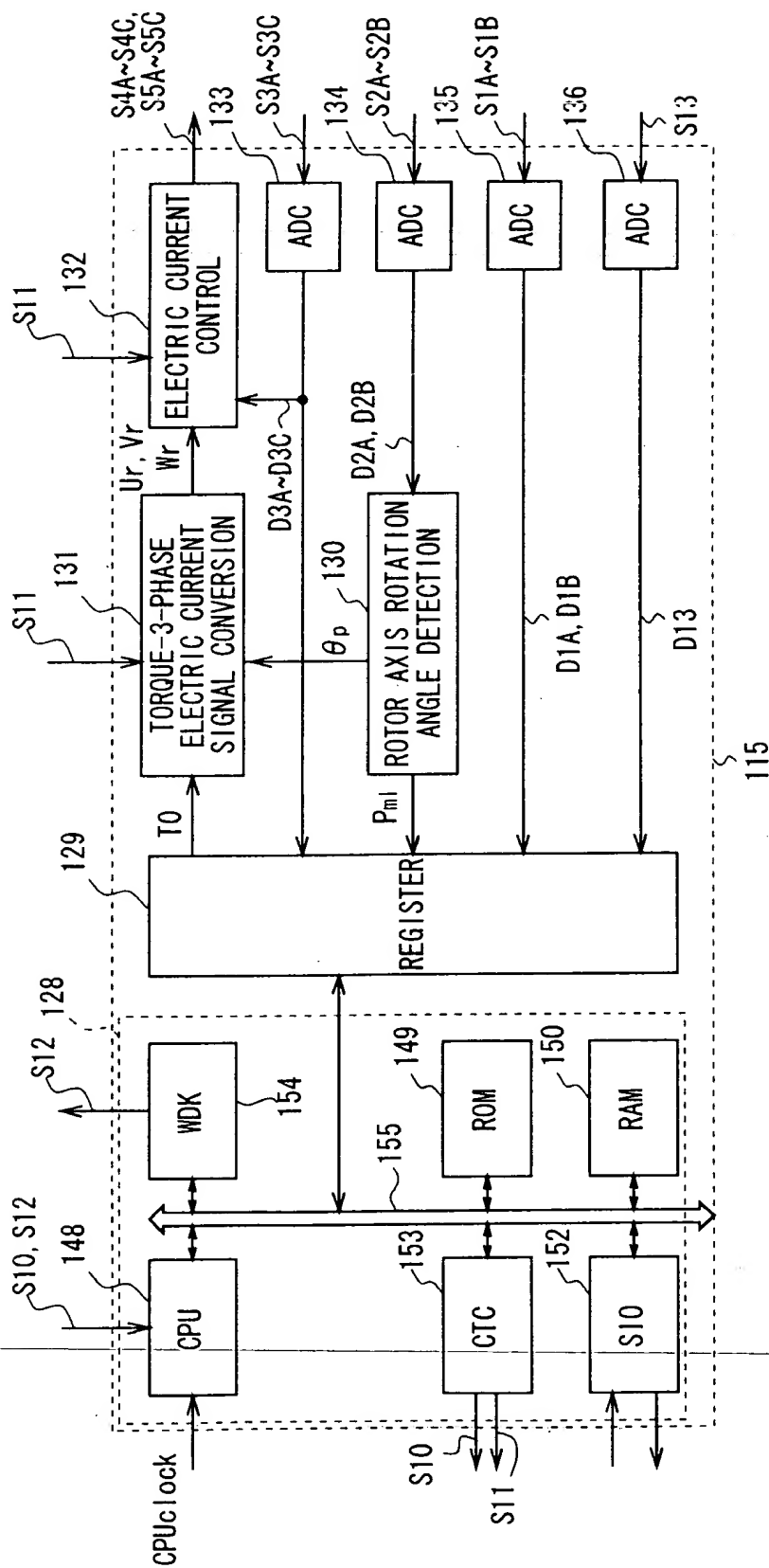
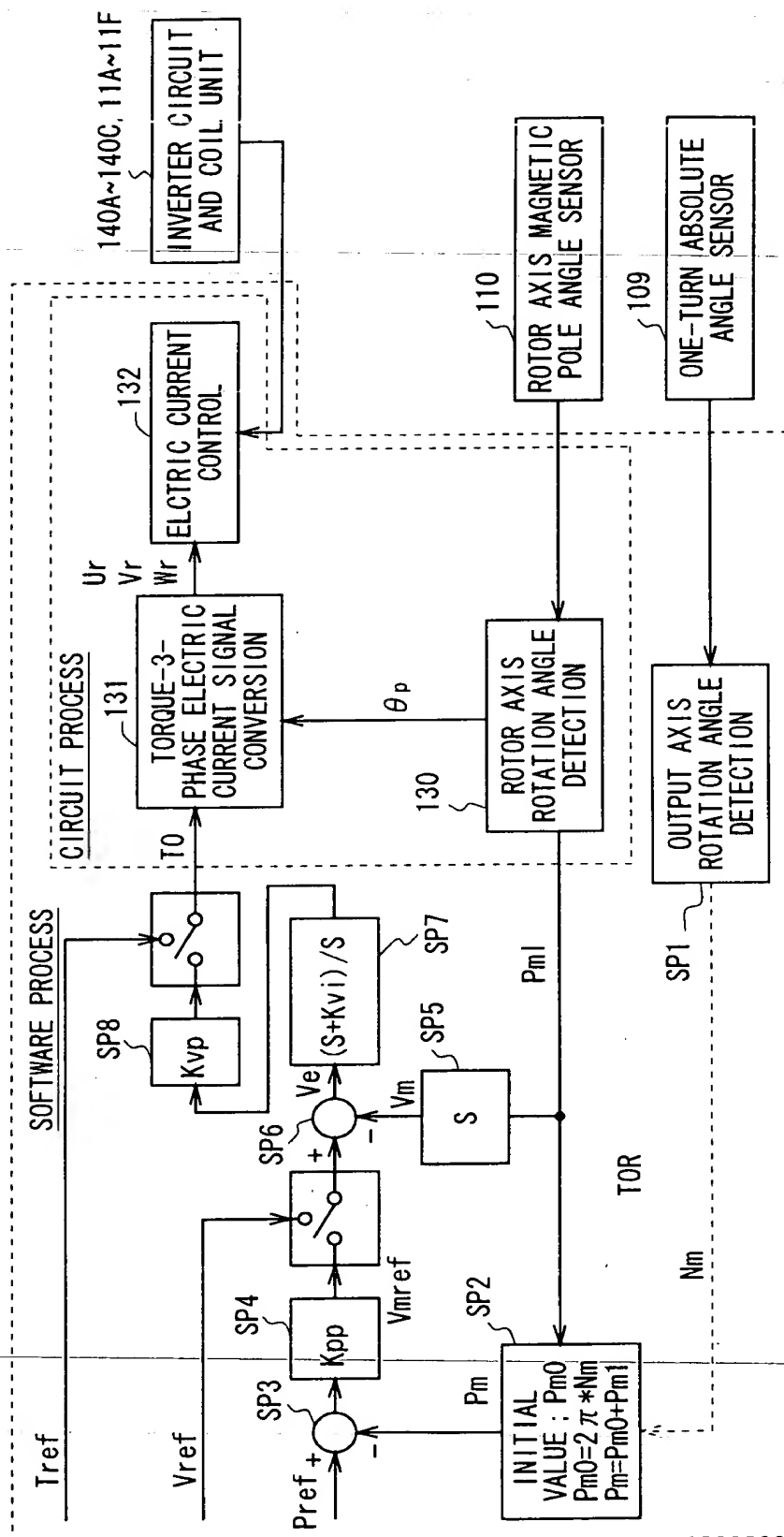


FIG. 19



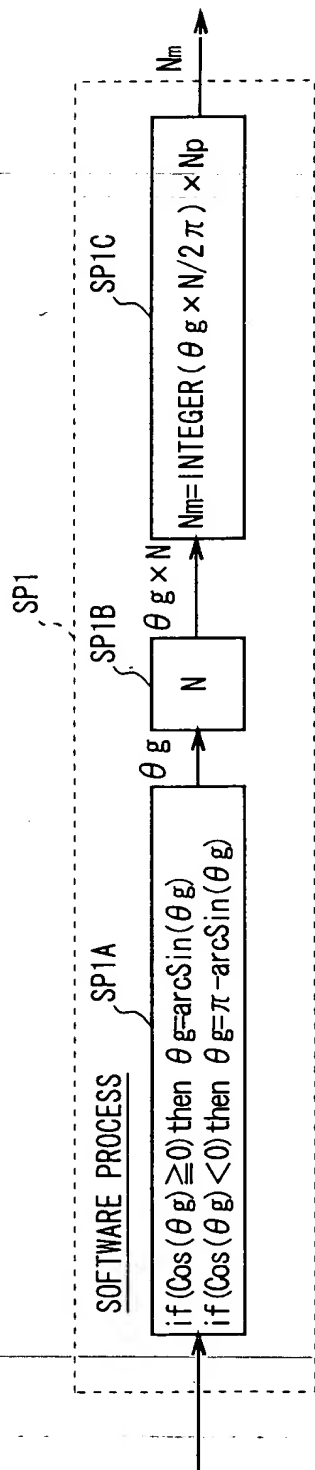


FIG. 21

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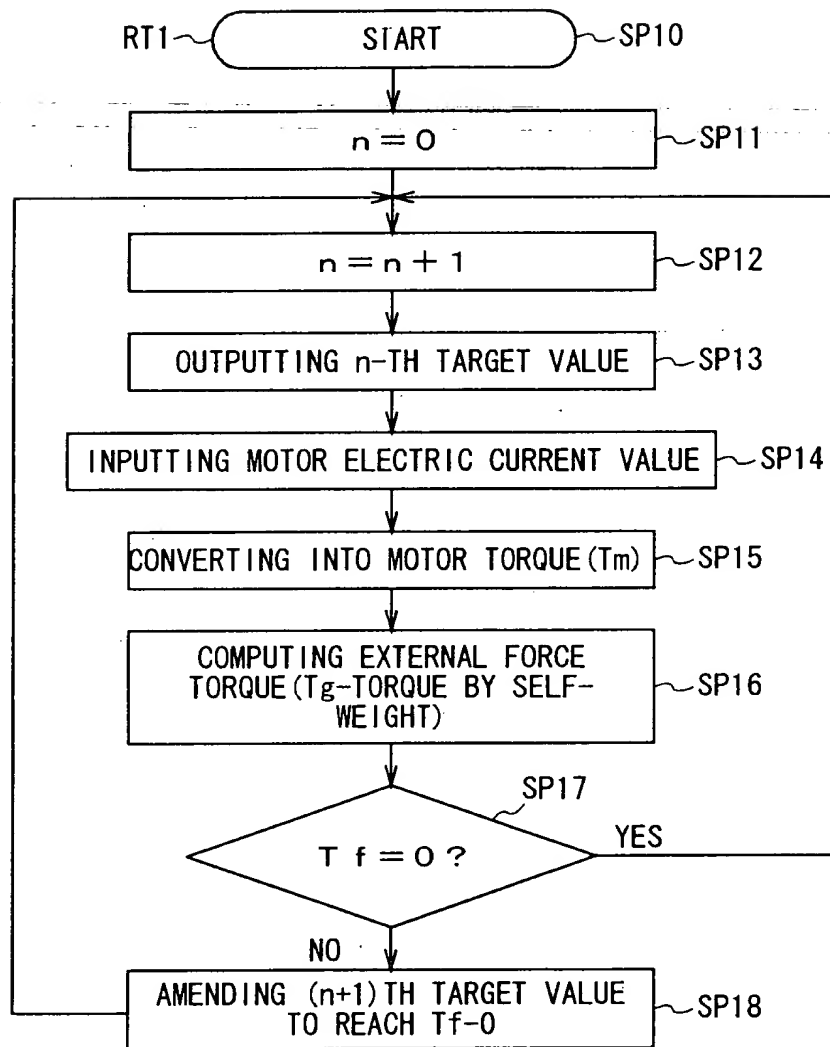


FIG. 22

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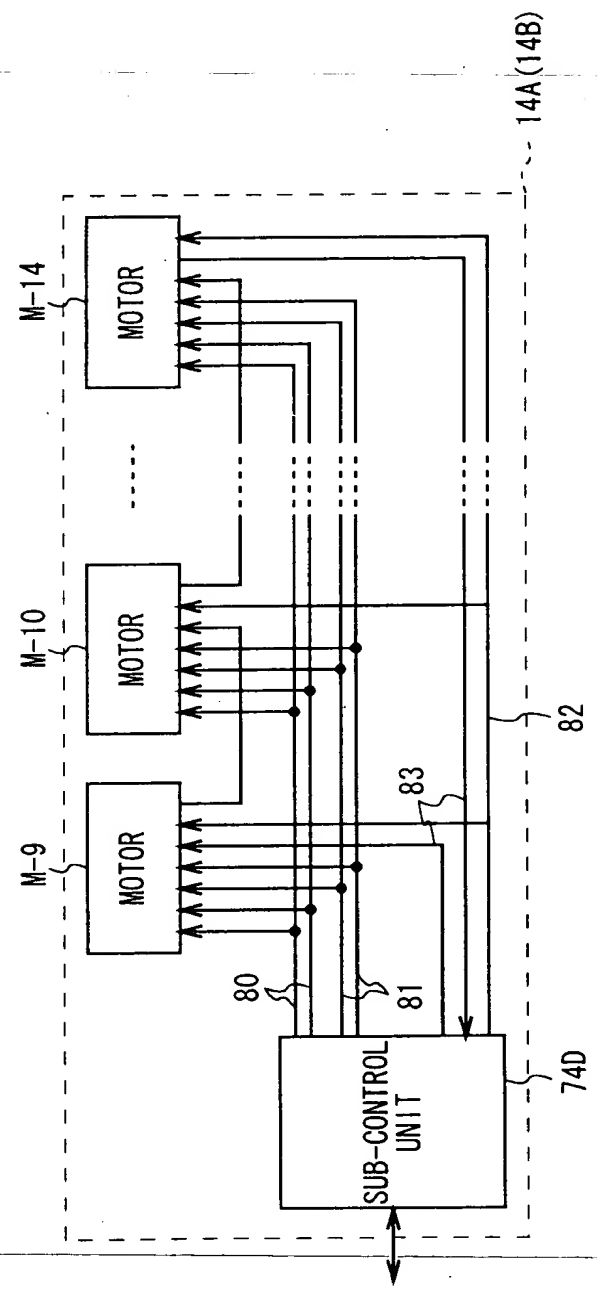


FIG. 23

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Explanation of Reference Numerals

10...robot, 11...belly unit, 12...head unit, 13A, 13B...arm units,
14A, 14B...leg units, 43...ankle joint mechanism, 44...foot unit,
70...main control unit, 73A through 73D...sub-control units,
106...output axis, 111...control substrate, 112...power substrate,
148...CPU, M-1 through M-14...motors, and RT1...unleveled ground
walking controlling procedure.

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